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L9 same (coordinate or co-ordinate)	6

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<u>L3</u>	L2 same (transform\$6 or translat\$4)	31	<u>L3</u>
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<u>L9</u>	L8 same (transform\$6 or translat\$5)	62	<u>L9</u>
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(pose <near/5> (boundar* or edge* or contour*)) <para|

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Results Key:

JNL = Journal or Magazine **CNF** = Conference **STD** = Standard

1 Assessing different features for pose refinement

West, G.A.W.; Tassone, E.;
Pattern Recognition, 2000. Proceedings. 15th International Conference on , Volume: 3 , 3-7 Sept. 2000
Pages:683 - 686 vol.3

[\[Abstract\]](#) [\[PDF Full-Text \(280 KB\)\]](#) **IEEE CNF**

2 Hybrid video using motion estimation

Baldwin, J.; Basu, A.; Zhang, H.;
Systems, Man, and Cybernetics, 2000 IEEE International Conference on , Vol. 2 , 8-11 Oct. 2000
Pages:1442 - 1447 vol.2

[\[Abstract\]](#) [\[PDF Full-Text \(524 KB\)\]](#) **IEEE CNF**

3 Position and pose detection of active camera-head in a nuclear power plant

Kita, Y.; Kita, N.;
Intelligent Robots and Systems, 2000. (IROS 2000). Proceedings. 2000 IEEE/ International Conference on , Volume: 3 , 31 Oct.-5 Nov. 2000
Pages:1872 - 1879 vol.3

[\[Abstract\]](#) [\[PDF Full-Text \(1184 KB\)\]](#) **IEEE CNF**

4 3-D object pose estimation based on iterative image matching: Shape and edge data fusion

Nomura, Y.; Dill Zhang; Sakaida, Y.; Fujii, S.;
Pattern Recognition, 1996., Proceedings of the 13th International Conference on , Volume: 1 , 25-29 Aug. 1996

Pages:513 - 517 vol.1

[\[Abstract\]](#) [\[PDF Full-Text \(392 KB\)\]](#) [IEEE CNF](#)

5 3-D object pose estimation by shading and edge data fusion-simulation and virtual manipulation on mental images

Nomura, Y.; Dili Zhang; Sakaida, Y.; Fujii, S.;

Computer Vision and Pattern Recognition, 1996. Proceedings CVPR '96, 1996 Computer Society Conference on , 18-20 June 1996

Pages:866 - 871

[\[Abstract\]](#) [\[PDF Full-Text \(484 KB\)\]](#) [IEEE CNF](#)

6 A real-time tracker for markerless augmented reality

Comport, A.I.; Marchand, E.; Chaumette, F.;

Mixed and Augmented Reality, 2003. Proceedings. The Second IEEE and ACM International Symposium on , 7-10 Oct. 2003

Pages:36 - 45

[\[Abstract\]](#) [\[PDF Full-Text \(986 KB\)\]](#) [IEEE CNF](#)

7 A graphics hardware implementation of the generalized Hough transform for fast object recognition, scale, and 3D pose detection

Strzodka, R.; Ihrke, I.; Magnor, M.;

Image Analysis and Processing, 2003. Proceedings. 12th International Conference on , 17-19 Sept. 2003

Pages:188 - 193

[\[Abstract\]](#) [\[PDF Full-Text \(480 KB\)\]](#) [IEEE CNF](#)

8 Estimating 3D hand pose from a cluttered image

Athitsos, V.; Sclaroff, S.;

Computer Vision and Pattern Recognition, 2003. Proceedings. 2003 IEEE Computer Society Conference on , Volume: 2 , 18-20 June 2003

Pages:II - 432-9 vol.2

[\[Abstract\]](#) [\[PDF Full-Text \(523 KB\)\]](#) [IEEE CNF](#)

9 Model-based tracking of human walking in monocular image sequences

Huazhong Ning; Liang Wang; Weinting Hu; Tieniu Tan;

TENCON '02. Proceedings. 2002 IEEE Region 10 Conference on Computers, Communications, Control and Power Engineering , Volume: 1 , 28-31 Oct. 2002

Pages:537 - 540 vol.1

[\[Abstract\]](#) [\[PDF Full-Text \(611 KB\)\]](#) [IEEE CNF](#)

10 Human standing pose detection proposing mean eigenspace

Masudar Rahman, M.; Ishikawa, S.;

Control, Automation, Robotics and Vision, 2002. ICARCV 2002. 7th International Conference on , Volume: 1 , 2-5 Dec. 2002

Pages:304 - 308 vol.1

[\[Abstract\]](#) [\[PDF Full-Text \(359 KB\)\]](#) [IEEE CNF](#)

11 Hand pose recognition using curvature scale space

Chin-Chen Chang; I-Yen Chen; Yea-Shuan Huang;
Pattern Recognition, 2002. Proceedings. 16th International Conference
on , Volume: 2 , 11-15 Aug. 2002
Pages:386 - 389 vol.2

[\[Abstract\]](#) [\[PDF Full-Text \(315 KB\)\]](#) [IEEE CNF](#)

12 On solving 2D and 3D puzzles using curve matching

Weixin Kong; Kimia, B.B.;
Computer Vision and Pattern Recognition, 2001. CVPR 2001. Proceedings of t
2001 IEEE Computer Society Conference on , Volume: 2 , 8-14 Dec. 2001
Pages:II-583 - II-590 vol.2

[\[Abstract\]](#) [\[PDF Full-Text \(949 KB\)\]](#) [IEEE CNF](#)

13 Model tracking for video-based virtual reality

Valinetti, A.; Fusello, A.; Murino, V.;
Image Analysis and Processing, 2001. Proceedings. 11th International Confer
on , 26-28 Sept. 2001
Pages:372 - 377

[\[Abstract\]](#) [\[PDF Full-Text \(680 KB\)\]](#) [IEEE CNF](#)

14 Visual servoing: path interpolation by homography decomposition

Borgstadt, J.A.; Ferrier, N.J.;
Robotics and Automation, 2001. Proceedings 2001 ICRA. IEEE International
Conference on , Volume: 1 , 2001
Pages:723 - 730 vol.1

[\[Abstract\]](#) [\[PDF Full-Text \(572 KB\)\]](#) [IEEE CNF](#)

15 Tracking of human activities using shape-encoded particle propagation

Moon, H.; Chellappa, R.; Rosenfeld, A.;
Image Processing, 2001. Proceedings. 2001 International Conference on , Vo
1 , 7-10 Oct. 2001
Pages:357 - 360 vol.1

[\[Abstract\]](#) [\[PDF Full-Text \(352 KB\)\]](#) [IEEE CNF](#)

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2	IS&R	L2	(348/169) .CCLS.	USPA	2004/09/01 10:59			0
3	BRS	L3	((pose\$1 or orientation\$1) near5 (new or current or start\$3 or initial or accurate\$4 or correct\$5 or true or proper) same (boundar\$3 or outlines\$1 or contours\$1)	USPA	2004/09/01 11:22			0
4	BRS	L4	3 same (associat\$5 or map\$5 or translat\$3 or transform\$6)	USPA	2004/09/01 11:02			0
5	BRS	L5	4 same (location\$1 or position\$3 or coordinate\$1 or co-ordinate\$1)	USPA	2004/09/01 11:03			0
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11	BRS	L11	63 10 same image\$1	USPA T	2004/09/01 11:13			0
12	BRS	L12	5 11 same (correspondence or map\$5)	USPA T	2004/09/01 11:14			0
13	BRS	L13	62 10 same (similar\$5 or match\$3)	USPA T	2004/09/01 11:14			0
14	BRS	L14	15 13 same (model\$1 or template\$1 or standard)	USPA T	2004/09/01 11:16			0
15	BRS	L15	5 3 same ((coordinate\$1 or co-ordinate\$1) near3 transform\$5)	USPA T	2004/09/01 11:16			0
16	BRS	L16	9 equation\$1 same ((pose\$1 or orientation\$1) near5 (new or current or start\$3 or initial or accurate\$4 or correct\$5 or true or proper) same (boundar\$3 or outline\$1 or contour\$1))	USPA T	2004/09/01 11:21			0
17	BRS	L17	6891 ((simultaneous or parallel) near5 (equation\$1 or mathematic\$4 or formula\$1))	USPA T	2004/09/01 11:22			0
18	BRS	L18	0 3 same 17	USPA T	2004/09/01 11:22			0
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22	BRS	L22	(("model\$1 or reference or template\$1 or standard or prestored) near3 patterns\$1)	USPA T	2004/09/01 13:41			0
23	BRS	L23	22 same (pose\$1 or orientation\$1 or position)	USPA T	2004/09/01 13:41			0
24	BRS	L24	106 23 same vector\$1	USPA T	2004/09/01 13:41			0
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26	BRS	L26	6 25 same (boundar\$3 or edge\$1 or contour\$1)	USPA T	2004/09/01 13:42			0
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28	IS&R	L29	0 ("06and27") .PN.	USPA T	2004/09/01 14:03			0
29	IS&R	L30	0 ("03and27") .PN.	USPA T	2004/09/01 14:04			0